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(54) Title: SYSTEMS AND METHODS FOR AN AUTOMATED, NEAR REAL-TIME, AND MOBILE IDENTIFICATION AND LOCALIZATION APPROACH WITH A COMBINATION OF BATTERY-LESS IDENTIFICATION MARKING TECHNOLOGIES AND PSEUDO RANGE-FREE LOCALIZATION ALGORITHMS

(57) Abstract: Embodiments of an automated and mobile identification and localization system and method for tracking both the final (stationary) and intermediate (transient) location of non-bulk resources and components are disclosed.

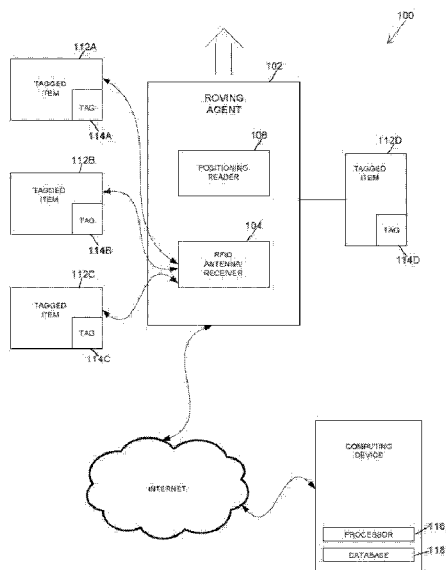


FIG. 3

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**PCT PATENT APPLICATION
FOR
SYSTEMS AND METHODS FOR AN AUTOMATED, NEAR REAL-
TIME, AND MOBILE IDENTIFICATION AND LOCALIZATION
APPROACH WITH A COMBINATION OF BATTERY-LESS
IDENTIFICATION MARKING TECHNOLOGIES AND PSEUDO
RANGE-FREE LOCALIZATION ALGORITHMS**

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CROSS-REFERENCE TO RELATED APPLICATIONS

[0001] This is a non-provisional application that claims benefit to U.S. provisional application serial number 62/151,034, filed on April 22, 2015, which is herein incorporated by reference in its entirety.

FIELD

[0002] The present disclosure generally relates to systems and methods for battery-less identification marking technologies to track the position of resources through their movement with a mobile (without fixed infrastructure of hardware assets) and near real-time approach, and in particular to non-bulk resources and components tracking system utilizing a novel combination of battery-less identification marking technologies, positioning services, and pseudo-range free localization algorithms.

BACKGROUND

[0003] The automated and precise location of non-bulk resource and components (e.g. engineered components, military supplies, cars, or general inventory items) in large, rough, or frequently unpredictable scenarios (such as those of civil engineering projects, war zones, car distribution, inventory management, etc.) is a challenging problem. In such scenarios, it is fundamental to be capable of exactly locating the components, so the right component is available for use by downstream processes at the right time and right place. For instance, the inability to locate a bolting tool or a pre-fabricated component required for installation on a project site have been observed to leave crane equipment and crews idle for several hours or even a full day. Similarly, the inability to locate a car in a common inventory and distribution yard also requires multiple hours, sometimes days, by crews. There is a need to properly and efficiently locate non-bulk resources or components over small or large areas (sometimes tens or hundreds of acres) in unpredictable, non-controlled, or dynamic scenarios.

[0004] Traditional manual tracking of resources and components tends to be time consuming, error prone, and inefficient. The solution needs an adequate blending of advanced technologies and reasoning mechanisms to facilitate the location of multiple, even thousands, resources/components over

extensive areas in short amounts of time and at inexpensive costs. Battery-less identification marking technologies are characterized by the data communication between a powered transmitter / receiver unit (also referred as transmitter, receiver, or reader) and a battery-less electronic identification device (typically referred as tag) through electromagnetic energy waves (e.g. radio waves). An example of such battery-less identification marking technologies is passive radio frequency identification (RFID).

[0005] Passive tags, as an example of battery-less identification marking technologies, operate without a battery source and offer low costs and interoperable communications with transmitters / readers, even though their technical limitations, such as a short range of communication from the tag to the reader (i.e. short read range or communication range). The lack of battery is indeed at the core of low passive tag costs. Passive RFID tags are, in essence, a coiled antenna connected to a circuit. The passive RFID tags make use of the magnetic energy of the incoming signal from the receiver to power a signal back to the receiver. FIG. 1 shows a typical communication of RFID receiver and tag. The battery-free characteristic of passive tags results in unit costs that range from a few cents to a few dollars. These unit costs are several orders of magnitude less than those of active (battery-powered) tags. This same battery-free characteristic also enables the physical design of tags in a large variety of shapes and sizes. For example, passive tags vary from flexible (similar to barcodes) to solid or encapsulated (similar to active tags). In addition to their low costs, the EPC UHF Generation 2 (or equivalent) standard guarantees the interoperability of passive tag and reader products. Virtually all passive products in the market are EPC UHF Generation 2 (or equivalent) compliant and hence interoperable. Thus, regardless of the manufacturer, the signal of any passive tag can be read and decoded by any reader and vice versa.

[0006] Despite the low costs and interoperability characteristics of passive RFID technologies, the need to keep passive tags and readers in very close proximity has historically limited their applicability. Indeed, a passive tag only emits in response to the reader signal (as opposed to active tags that continually emit beacon signals) and actually obtains its power from that signal. The reader signal is captured by the inductive coil antenna, which, at the same

time, energizes the tag and supplies the power to respond back to the reader. Thus, passive tags emit weak signals and hence can only communicate with the reader if this is within a short communication range.

[0007] An automated and mobile identification and localization infrastructureless approach with a combination of active (battery assisted) RFID technologies and range-based algorithms is known. Even though the evident cost benefits of such, the actual upfront cost of active RFID tags (starting at \$30 per unit) tremendously limits its actual application. Consumers of such approaches (contractors, defense, inventory management, supply chain, etc.) need to tag hundreds of thousands of items, each of them with a costly tag. In addition, in the previous approach, the antenna and receiver were placed in a mobile roving unit that must be able to circulate nearby the tagged components, so it can collect multiple unique signals for each tag, at the same time it collects the GPS position of the rover. Such ability to circulate close to any tagged component is often not possible at the expense of inaccurate location results. The aim of this previous active-RFID and mobile approach is to generate a unique location estimate (assumed as a stationary or non-moving condition) for all the tagged components with batch or discrete data collection efforts, i.e. without a real-time component. With this approach and given the (often) long physical distances between reader(s) and tags during the data collection in combination with the presence of obstacles and other signal attenuation issues affecting the signals traveling between distant reader(s) and tags, and even more when the components are spread in large areas and hence data collection efforts by roving units are minimized, there is no guarantee that a location can be estimated for all the tagged components, or that such location(s) can be accurate. Thus, the location of certain components is often lost and hence such components cannot be tracked. In any case, all that can be initially known from a tagged component is that it lies somewhere around the rover position in a radius equivalent to the communication range of the active radio frequency devices, typically in the range of hundreds to thousands of feet.

BRIEF DESCRIPTION OF THE DRAWINGS

[0008] FIG. 1 is a simplified illustration showing a prior art radio frequency identification system;

[0009] FIG. 2 is a picture showing passive tracking system;

[0010] FIG. 3 is a simplified illustration showing the passive tracking system; and

[0011] FIG. 4 is a flow chart illustrating one method of operation for the passive tracking system.

[0012] Corresponding reference characters indicate corresponding elements among the view of the drawings. The headings used in the figures do not limit the scope of the claims.

DETAILED DESCRIPTION

[0013] Various embodiments of a passive tracking system for determining the exact location of a moved item tagged with a passive radio frequency identification (RFID) tag are disclosed. In some embodiments, the passive tracking system includes a roving agent that moves among a plurality of tagged items in which the roving agent includes a positioning reader (e.g. Global Positioning System) and radio frequency identification (RFID) transmitter/receiver (with antennas) co-located in the roving agent. In some embodiments, the roving agent is used to translocate (lift, handle, and/or direct the movement) of one or more items tagged with a passive RFID tag. In many embodiments, the roving agent may be a moving vehicle, such as a forklift or a crane, although in other embodiments, the roving agent may be a person, such as an equipment operator, driver, or an individual possessing a computing device, such as smart phone or portable computing device having position locating capability and an RFID antenna/receiver that allows for the determination of the position of a tagged item being moved as well as identify the moved tagged item. In some embodiments, an RFID transmitter/receiver is secured to the roving agent and its antenna specifically directed or not (depending on the type of antenna used) towards the roving agent that is going to handle the tagged items (for instance, the forks in case of the forklift) as illustrated in FIG. 2. At the same time, a battery-less identification-marking device, such as an inexpensive passive RFID tag, is physically attached to each tagged item. Each passive RFID tag **114** has a unique identification code, which is associated with the (commonly unique) piece mark of the tagged item (or pallet / group of tagged items). Given the short communication range of passive RFID tags **114**, the RFID antenna/receiver **104** will only read the passive RFID tags of tagged items **112** near the location of the roving agent **102** (e.g. fork or hook for cranes). At a predefined interval (for instance 1 or 2 seconds), the positioning receiver, such as a GPS, computes the positional coordinates of the roving agent while the RFID antenna/receiver detects and identifies the nearby tagged item through its unique passive RFID tag.

[0014] Referring to FIG. 3, a description of one embodiment of the passive tracking system, designated **100**, is illustrated. The passive tracking system **100** utilizes the short communication range of the battery-less or passive RFID tag **114** associated with a particular tagged item **112** to guarantee that a tagged item(s) **112D** being hauled by the roving agent **102** will be consistently identified over time and distance during translocation (between pick up and drop off) of the tagged item **112** by the roving agent **102**, while those tagged items **112A-C** positioned along and nearby the path of the roving agent **102** (but not hauled by the roving agent **102**) will only be identified when in close-proximity to the roving agent **102** when the tagged item **112** is within the short communication range of the passive RFID tag **114** attached to the stationary tagged item **112A**, **112B** and **112C**. This consistent identification of moved tagged items **112** during translocation of each tagged item **112** by the roving agent **102** is used to determine the final location of that tagged item **112**, while discarding false stationary tagged item **112** positions, e.g. as a result of temporary stops by the roving agent **102** or the nearby presence of the RFID antenna/receiver **104** (collocated with the roving agent **102**) in a stationary or semi-stationary mode. In some embodiments, the roving agent **102** may include a positioning reader **106**, such as a GPS, that provides positional data of the roving agent **102** to a computing device **110** when a particular passive RFID tag **114** is detected. In some embodiments, the computing device **110** includes a processor **116** that receives the positional data of the roving agent **102** and the related identifying data of the detected passive RFID tag(s) **114** by the RFID antenna/receiver **104** of the roving agent **102**. In some embodiments, the positional and identifying data of each detected tagged item **112** may be stored in a database **118** by the processor **116**. In some embodiments, the database **118** may store the positional and identifying data of all the stationary tagged items **112** in inventory and then this location information for each tagged item **112** may be updated anytime the roving agent **102** moves one or more tagged items **112** from its original location to a new location. In this manner, the location of each tagged item **112** may be updated every time a tagged item **112** is moved from one location to another location by the roving agent **102**.

[0015] In some embodiments, the computing device **110** may be a computer, such as a portable computer, tablet, or smart phone capable of receiving and storing positional and identifying information in a database. In some embodiments, the positioning reader **106** may be a GPS embodied in a mobile phone having GPS capability that is in operative communication with the computing device **110**. In some embodiments, the roving agent **102** includes a transmitter (not shown) that transmits both the positional information from the positional reader **106** and identifying data of the detected passive RFID tag(s) **114** to the computing device **110** through the Internet and/or a wireless communication capability known in the art.

[0016] For instance, Table **1** shows an example in which three tagged items **112** (1, 2, and 3) are translocated over two coordinated locations by a roving agent **102**. During the movement of the tagged items **112** by the roving agent **102** several other passive RFID tags **114** associated with tagged items **112** that are stationary and in proximity to the roving agent **102** may be detected and identified by the RFID antenna/receiver **104**. Nonetheless, with the passive tracking system **100** there is the guarantee that only the tagged items **112** being moved by the roving agent **102** may be identified due to the limited range of communication (typically 5 feet or less) of the passive RFID tags **114** of the stationary tagged items **112** by the RFID antenna/receiver **104** associated with the roving agent **102**. According to this reasoning, Tags 1, 2, and 3 are dropped at Position 7 at Time 7.

Table 1. Logic Localization Reasoning

Time 1	Time 2	Time 3	Time 4	Time 5	Time 6	Time 7	Time 8
Position 1	Position 2	Position 3	Position 4	Position 5	Position 6	Position 7	Position 8
Tag 1,2,3	Tag 1,2,3,10	Tag 1,2,3,10	Tag 1,2,3,23	Tag 1,2,3,25	Tag 1,2,3	Tag 1,2,3,33	Tag 33

[0017] The accuracy error of passive tracking system **100** is limited to the communication range of the passive RFID tags **114** (a few feet only). Indeed, field trials were used to validate such approach for two different types of passive RFID tags **114** with very accurate location results. Such results are provided in the Table **2**.

Table 2. Test Results

	Straight line(m)		Path (m)		Distance error(m)		0-3(m)	3-6(m)	6-9(m)	>9(m)
	Avg	STDEV	Avg	STDEV	Avg	STDEV				
Xefray	12.94	1.86	18.42	2.16	4.53	1.34	20%	73.33%	6.67%	0
Troi 2	12.94	1.86	18.42	2.16	1.26	0.38	100%	0	0	0

[0018] Referring to FIG. 4, one method of operation for the passive tracking system **100** is described. In some embodiments, the method utilizes a processor **116** (FIG. 3) to process information related to the readings of various passive RFID tags **114** (FIG. 3) is illustrated. The process may begin by a buffer being retrieved from the database **118** with a sequence of previous positions and times for one or more passive RFID tags **114** detected by a roving agent **102**. A time is read for a given frequency of each passive RFID tag **114** detected within detection range of the roving agent **102**. If the identification and signal strength from any passive RFID tag **114** is detected at a given time, the position of the roving agent **102** is also read at the exact same time and such position information is associated with the identification, signal strength, and time information. For a given passive RFID tag **114**, the time series of signal strength and position information are accumulated. Once the same time identification signal is not detected any longer by the RFID antenna/receiver **104** in the roving agent **102**, a time series analysis first determines whether the tag **114** was traveling with the roving agent **102**. If the tag **114** had been traveling with the roving agent **102**, the same time series analysis technique is used to assess the total travel distance. Pseudo range free algorithms in combination with the time series analysis are used by the processor **116** to compute the estimated final and current position of the detected tag **114**, and the travel path to the from the start or origin position to the final position of the roving agent **102**. A combination of Bayesian statistics and machine learning reasoning executed by the processor **116** aims at enhancing the accuracy of the final position estimate. Such Bayesian statistics and machine learning reasoning can become essentially different if the tag **114** has traveled above a certain threshold (e.g. several times the read range of the passive RFID tag **114**) or not (e.g. below or about the read range of the identification tag). The same time-series analysis, pseudo range free algorithms, Bayesian statistics and machine learning are also executed by the

processor **116** to ascertain the first tag **114** position, i.e. the origin of the travel path of the roving agent **102**, so that such path can be computed. In either case, the new tag **114** position (X,Y,Z) is updated in the database **118** along with the corresponding time information. The travel path of tag **114** (time series of locations) from the original position to the final or current tag **114** position is also computed and stored in the database **118**. If the tag **114** did not travel with the roving agent **102**, evidence that the tag **114** was or was not stationary near the roving agent **102** is sought with time series analysis. If evidence that the tag **114** was actually stationary around the nearest location (for instance, based on signal strength) where the roving agent **102** identified the tag **114** exists, such location is compared with the previous position for the same tag **114** that the buffer initially retrieved from the database **118**. If the location of the roving agent **102** where the tag **114** was identified and the previously recorded position for the same tag **114** in the database **118** are similar below a certain threshold of discrepancy (measured in distance, for instance below the tag **114** read range), then the previous recorded position is kept and the tag **114** position is not updated. Evidence of the identification of the tag **114** by the roving agent **102** is stored in the database **118** for potential future inferences, for instance by machine learning and Bayesian probability reasoning. On the contrary, if the location of the roving agent **102** where the tag **114** was identified and the previously recorded position for the same tag **114** in the database **118** are distant above the threshold of discrepancy, pseudo range free algorithms and time series analysis are used to estimate a new position for the tag **114**. Bayesian statistics and machine learning executed by the processor **116** are used to improve the accuracy of the new estimated tag **114** position. The new tag **114** position is stored in the database **118** along with the corresponding time. In case the tag **114** was neither traveling with the roving agent **102** nor stationary –for example the tag **114** was actually moving with another roving agent **102**, the time series of collected data (identification and location) are stored as future evidence and analyzed by machine learning to ascertain an explanation and also learn on how to make future inferences based on data from similar situations., then the identification and signal strength of each passive RFID tag **114** is read.

[0019] However, if the identification and signal strength is not read, then the location of the passive RFID tag **114** is read before proceeding further in the process. In addition, the passive RFID tags **114** that are potentially traveling with the roving agent **102** are estimated by the passive tracking system **100**. The passive RFID tags **114** that were traveling, but are now stationary, are then determined by the processor **116**. The buffer is then updated with the latest position and time for each passive RFID tag **114** before the buffer information is saved to a database **118**. Bayesian statistics/machine learning then occurs based on the information provided before proceeding back to either further update the buffer with the latest time and position of each passive RFID tag **114** or update the buffer is again with the latest positions and times of each passive RFID tag **114** before the Bayesian statistics/machine learning is saved to the database **118**. Once the information is saved, the process proceeds back to once again to retrieve a buffer from the database **118** with a sequence of positions and times for one or more passive RFID tags **114**.

Process

[0020] In some embodiments, the processor **116** may execute instructions for the following method to effectuate the operation of the passive tracking system **100** discussed above.

COLLECTION OF RFID ID AND (X,Y,Z) POSITIONING DATA
 Set STOP = False
 ENTER Reading Frequency (integer, e.g. 1 second)

While STOP = False

-DATA COLLECTION - Read location, time, signal intensity and IDs-
 WHEN $t_{i+1} = t_i + \text{Reading Frequency}$
 Read tag IDs (i.e. nearby roving unit) and corresponding RSSI
 Read location coordinates (X, Y, Z)
 END WHEN

END WHILE

FINAL AND INTERMEDIATE LOCATIONS ESTIMATION
 - Assess moving and potentially moving tags-
 FOR each ID discovered at t_{i+1}
 ID Count = ID Count + 1

END FOR

ti+1 -Adjudicate tag position if tag was traveling with agent and is stored at

FOR each TAGID

-tag was potentially traveling with agent
IF TAGID Travel > threshold of minimum travel distance (e.g. 15ft)

-Assess whether tag could have been stored
IF TAGID not detected at ti+1

-Determine actual tag position from time series of consecutive (X,Y, Z) readings based on a minimum threshold of RSSI (PSEUDO RANGE FREE APPROACH)

SELECT (X,Y,Z) location before maximum or trend (RSSI) started to decrease

-Confirm that distance from (X,Y,Z) location at ti-n selected above to latest (X,Y,Z) location at ti+1 is above a threshold

IF not confirmed

Use Bayesian statistics and machine learning to assess most likely actual position (X,Y,Z) based on the combination of probability statistics and past occurrences

END IF

-Assess whether component was actually moved from latest stored position, e.g. that equipment was not idle

IF distance between estimated actual position (X,Y,Z) at time t and previous accepted position (X,Y,Z) at time t-n is larger than minimum threshold

-Use previous knowledge to refine position estimate. Use Bayesian statistics and machine learning to identify patterns or trends in the location estimate of the tag in order to use previous (and successful) reasoning mechanisms

UPDATE actual position to (X,Y,Z)

UPDATE translocation path and time as a series of (X,Y,Z, t) values, from initial to final positions

ELSE

KEEP previous stored position –do not update

END IF

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END IF

    Assess tags not travelling with agent unit
    IF TAG was not travelling with agent unit

        Used time series analysis to determine whether tag was
stationary

        Assess if new position exists for stationary tag
        IF TAG was stationary
        Compare previous position with location where roving object detected it

        Compute new position
        IF DISCREPANCY in positions
        Compute new position with time series analysis, pseudo range-free
location algorithms, Bayesian statistics, and machine learning

        IF NOT

            Keep previous position – do not update

                IF TAG NOT STATIONARY

                    Store evidence

                        Use machine learning from previous instances to explain tag condition,
for instance tag passing by in a different roving unit

                            END IF

                                END IF

                                    END IF

                                        END FOR

                                            -Reset counter for tag IDs without discontinued identification at ti+1
FOR each TAGID discovered at ti-n,..., ti but not identified at ti+1
        Tag ID Counter = 0
END FOR

```

[0021] The process described above may include software instructions executed on a processor **116** in operative communication with the RFID antenna/receiver **104** of a roving agent **102** that travels through an area having a plurality of items **112** tagged with a respective passive RFID tag **114**. The passive tracking system **100** makes inferences on the identified passive RFID tags **114** [those, if any, carried by the roving agent **102**, and also those

passive RFID tags **114**, which are stationary (not moving) or non-stationary (e.g. as carried by another roving agent **102**), nearby the path of the roving agent **102** at any moment in time, but not moved by the roving agent **102**. By combining information on the series of passive RFID tags **114** identified over time and the corresponding positions of the roving agent **102** when a particular passive RFID tag **114** is detected. The process of the passive tracking system **100** makes use of pseudo-range free algorithms, time-series analysis, Bayesian statistics and machine learning to infer the most likely final location of the tagged items **112**, as well as their travelling path, i.e. the multiple intermediate or non-stationary locations, to get to such final location coordinates of the tagged items **112**. While the time-series analysis identifies the tagged items **112** actually being moved as opposed to the nearby tagged items **112** along the path of the roving agent **102**, and inter travel distances, pseudo range-free location algorithm is designed to determine both the initial (before being moved) and final tag (after being moved) positions. The update on a tagged item **114** position is generated with the evidence that the tagged item **114** has been placed in the new position, i.e. in near real-time. Even though process executed by the processor **116** is in essence range free, i.e. algorithm does not directly infer distances or location from the intensity (RSSI) information, the process actually makes use of the intensity information (pseudo range-free algorithm) to decide what identification and positioning data for a particular tagged item **112** needs to be processed in order to increase the accuracy and certainty of the final (stationary) and intermediate (during translocation) tagged item **114** locations (X, Y, Z). Bayesian statistics and their belief functions and machine learning reasoning are used to refine and ascertain the likelihood of the final location of the tagged item **112** in a general manner, and in specific situations that increase the uncertainty and complexity of the location process. For example, short translocations of tagged items **112**, below or about the tag **114** read range, can only be assessed using such probabilistic and reasoning approaches, and partially based on the learning from previous similar instances of events and/or feasibility tests. Indeed, the Bayesian statistics and machine learning components aim at improving the degree of location accuracy for the new set of X,Y,Z coordinates, even more in certain type of situations that add uncertainty to the location

process, and, even then, whether the likelihood of the new position in the event of previous history of true and false positives / negatives, and hence inclusive of the evaluation on the success, of previous similar type of assessments through machine learning. Time series analysis are also used to contrast the coordinates generated by the roving agent **102** when passing nearby a stationary (non-moving) tagged item **112** with the last known or recorded stationary coordinates of the same tagged item **112**. Hence, any potential evidence of discrepancy in the final position of a tagged item **112**, for instance in the case that the distance between a moving roving agent location when detecting a stationary item with a given communication range and the latest recorded position for the same tagged item **112** is multiple times such communication range, could be identified and immediately reported to trigger any corrective actions. In such case, the same combination of time series analysis, pseudo range-free algorithms, Bayesian statistics, and machine learning are also used to infer the new position of the stationary and tagged item. In case the tag **114** was neither traveling with the roving agent **102** nor stationary –for example the tag **114** was actually moving with another roving agent **102**, the time series of collected data (identification and location) are stored as future evidence and analyzed by machine learning to ascertain an explanation and also learn on how to make future inferences based on data from similar situations.

[0022] The advantages of the passive tracking system **100** are the following:

[0023] 1. Large benefit to cost ratio. Inexpensive battery-less identification marking technologies, such as passive RFID tags **114**, even though with a much shorter communication range, can be used to track tagged items **114** with the passive RFID system **100**. The cost of each passive RFID tag **114** ranges from cents to a few dollars, and hence allows the approach to be much more cost effective.

[0024] 2. Precise location. While the previous mobile approach with active RFID results in location accuracies that range from a few feet to 30 or 50 feet, the passive tracking system **100** implemented through passive RFID technology consistently results in reduced location errors, as shown in the table above. Partially, this advantage comes from the computation of the

location of the tagged item **112** without the computation of any signal characteristic but with its consideration (pseudo range-free approach). Thus, the computing approach is much simpler and, at the same time, robust to the unpredictability common to open field scenarios. For instance, war zones, civil projects, or distribution areas are characterized by the presence of large moving obstacles, such as tanks, construction equipment, cars, containers, etc., variable weather conditions, or the presence of materials (wood, liquids) with properties that can significantly attenuate electromagnetic and radio waves.

[0025] 3. Passive RFID approaches are interoperable. As such, there is a standard of communication that allows tags, readers, and antennas from different suppliers to communicate with each other; however, such standard does not exist for active RFID tags, implying that a company willing to embrace active RFID is actually betting on the products to be deployed and on the survival of the manufacturer or provider of such products. The adoption of active RFID implicitly brings a risk associated with the adopted product.

[0026] 4. Use of an infrastructure-less tracking approach. As a difference with indoor localization systems (for instance Real Time Location Systems or RTLS), in most unstructured environments the utilization of a stationary infrastructure (stationary antennas, poles, receivers, power and communication cables) would obstruct the processes or operations, and hence it is not an option. In addition, such stationary infrastructure results in prohibitive costs when implemented over extensive or large areas such as war zones, construction projects, inventory areas, or distribution areas.

[0027] 5. When compared to the existing active RFID approach, the passive tracking system becomes extremely much more efficient, since, essentially, a component is only tracked when it is being moved. In the conventional active RFID approach, the current practice is to track the stationary (even though such stationary condition is not guaranteed) location of all (frequently thousands of) tagged items **112** several times a day.

[0028] 6. Thus, the main difference, from a conceptual perspective, is that the location and identification tracking approach of the passive tracking system **100** is embedded into the process that moves, hauls, or transports the tagged items **112**, and that such tracking is limited to the

moment when the tagged item 112 is left in its final position. Previous approaches (both manual and with active RFID) were based on that the localization and identification approach had to be performed on the stationary condition of the tagged items, i.e. separately from the process of changing the location (or moving) the tagged items **112**. Thus, a tagged item **112** could be changed from one location to another location, and, if new data had not been collected since such movement, the localization records of the tagged item **112** would reflect its old position and hence the tagged item **112** would likely not be located. Thus, the previous approaches aim at routinely tracking all the stationary tagged items **112** in order to generate a single estimate of the stationary location for all the tagged items **112**. In the passive tracking system **100**, a tagged item **112** is only tracked when it is translocated from a position to a different (or eventually the same) position, and location estimates are generated not only for its final or stationary location but also for its multiple sequence of intermediate or non-stationary locations during the movement.

[0029] 7. *Near real-time and continuous update of positions.* A new final position is generated immediately after (e.g. a few seconds) the identification reader in the roving agent **102**, which has positioned the tagged items **112** in its final location, moves away from the tagged items **112** and eventually loses contact with the corresponding tag. In this passive-identification and mobile approach of the passive tracking system **100**, the positions of the tagged items **112** are continuously updated as the tagged items **112** are moved, in near real-time. In the conventional active RFID approach, data is collected for all the tagged items **112** at a predefined frequency, i.e. in a batch mode, and hence there is no real-time visibility of the actual tagged item **112** positions. In such discrete and batch data collection mode, the positions of the tagged items **112** age with increments in the time intervals between data collection efforts. For instance, a one-time-a-week data collection effort implies that positions are 7-day old right before each data collection effort.

[0030] 8. *Highly accurate and reliable location estimation based on proximity reasoning.* The short distance(s) between the identification reader in the roving agent and the tagged items **112** being hauled by the roving agent **102** virtually guarantees (for instance with the exception of hardware

malfunctioning issues) that location estimates can be generated by the translocated components. In the conventional RFID-active mobile approach, given the (often) long physical distances between reader(s) and tags during the data collection in combination with the presence of obstacles and other signal attenuation issues affecting the signals traveling between distant reader(s) and tags, and even more when the tagged items **112** are spread in large areas and hence data collection efforts by roving units are minimized, there is no guarantee that a location can be estimated for all the tagged items **112**, or that such location can be accurate. Thus, the location of certain tagged items **112** is often lost and hence such tagged items **112** cannot be tracked. On the contrary, the passive tracking system **100** virtually guarantees not only the location of a tagged item **112**, but also that such location is nearly identical to the actual tagged item **112** position. In addition, the passive tracking system **100** also contrasts the coordinates generated by the roving agent when passing nearby a stationary (non-moving) tagged item **112** with the last known or recorded stationary coordinates of the same tagged item **112**. Hence, any potential evidence of discrepancy in the final position of a tagged item **112**, for instance in the case that the distance between a moving roving agent location when detecting a stationary tagged item **112** with a 10 ft communication range and the latest recorded position for the same tagged item is larger than such communication range, could be identified and immediately reported to trigger any corrective actions.

[0031] 9. *The passive tracking system **100** enables the efficiency assessment for the processes associated with the movement / translocation / hauling of resources / components / items.* On top of the ability to provide the stationary or final location of tagged items **112**, the passive tracking system **100** also provides the non-stationary locations during the translocation of a tagged item **112** and hence enables the efficiency assessment of the processes associated with such translocation. For instance, in car inventory management, the efficiency of the inventory process can be observed by analyzing the translocation data, such as the average number of times a car has been moved, the length (in distance and/or time) of such movements, paths of movement, or the amount of time required to retrieve and deliver a solicited car unit. Conventional automated and mobile identification

and localization infrastructureless active-RFID approaches only provide stationary tagged item **112** data and hence translocation operations are not visible and, as a result, their efficiency cannot be assessed.

[0032] 10. *A novel pseudo range-free localization reasoning approach is used to estimate final (stationary) and intermediate (non-stationary) positions.* Conventional RFID-active approaches to localization of stationary assets depend on either triangulation or time-of-flight mechanisms for infrastructure-based approaches (e.g. RTLS), most of them range based, or optionally, range free. Indeed, existing approaches to track locations are mostly based on algorithms that make use of RSSI (intensity of the RFID tag signal as captured by a receiver) information to infer distances between an identification tag and receiver(s), and hence estimate the tag location, i.e. range based, or eventually that do not make use of the RSSI intensity data at all, i.e. range free. As a departure from current reasoning algorithms, the localization approach of the passive tracking system 100 is pseudo range free. Thus, even though it does not make use of the signal intensity data to infer distances or locations, it dynamically sets a minimum RSSI threshold value in order to select the signals from a specific tag that will be used to estimate the location of the corresponding tagged item with the final goal to improve the accuracy of such location. The stronger the RSSI signal is, the more certain the proximity between the tagged item and the antenna becomes. On the opposite, that a signal is weak does not necessary imply that antenna and tagged item are distant from each other, they could actually be next to each other or distant; there is no certainty. Thus, supported by machine learning and Bayesian statistic reasoning, the RSSI threshold value is used to improve the estimated location accuracy of the tagged item without loosing granularity or data collection evidence. For example, the minimum signal intensity threshold value may be set to a strong intensity value for determining the location of a tagged item for which multiple signals have been collected, but a weak intensity threshold may be set when the number of data points is scarce. Thus, the pseudo range-free algorithm does not use the signal strength to infer distances or locations but such RSSI intensity is dynamically set and leveraged to improve the accuracy of the estimated locations. Eventually, though, the pseudo-range free algorithm could process all the signals from a given tag

irrespective of their intensity, e.g. in the case that such signals were all above the predefined threshold of intensity. In such case, the pseudo-range free algorithm would be conceptually equivalent to a range-free approach.

[0033] The passive tracking system **100**, though, is characterized by the following traits:

[0034] The localization and identification process of the passive tracking system **100** is embedded in the operations and processes that translocate the tagged items **112** and enables the assessment of efficiency on such operations. Thus, if a tagged item **112** is translocated, new data may be collected. If the component is not moved, its position record will not change. There is always a correspondence between the component position and its localization records. There is no need to run repetitive localization and identification efforts for all the (stationary) tagged items **112**. Assuming that the tagged items **112** need to be moved by a machine (forklift) or even manually, such machine or person agent will automatically provide the collection for the data that will result in the new localization of the tagged item **112**.

[0035] The passive tracking system **100** can be used to track resources or components in an inexpensive manner using passive RFID technology. The passive tracking system **100** can be applied to any situation in which a large number of tagged items **112** must be managed and tracked in order for the right tagged item **112** to be instantaneously located, so that it can be retrieved to the right location and at the right time.

[0036] The passive tracking system **100** focuses on tracking the process of moving tagged items **112** as opposed to tracking the tagged items **112**. In some embodiments, the passive tracking system **100** determines location estimates based on a proximity approach as opposed to conventional active RFID tracking solutions that utilize triangulation and other similar algorithms to determine location based on multiple readings from the same component to a fixed network of antennas to provide an accurate location estimate.

[0037] The passive tracking system **100** may enhance the identification and localization of non-bulk resources and items in dynamic and / or unpredictable environments with a reduced upfront and maintenance cost. Industries that may want to make use of this approach include:

- Civil engineering and construction projects.
- Inventory or distribution management, e.g. in the car industry.
- Logistics, both indoors and outdoors.
- Manufacturing.
- Defense (specifically logistics and war scenarios) for material and cargo supplies.
- Supply chain management.

[0038] Such identification and localization may be useful, in regards to the tagged items, to:

- Track tagged items.
- Operate and maintain items (for instance, valve components in industrial facilities).
- Distribute items.
- Assess the efficiency of processes (e.g. inventory, distribution, supply chain, construction, manufacturing, etc.).

[0039] The benefits of passive tracking system **100** include cost and availability of technology is as follows:

[0040] COST and AVAILABILITY OF TECHNOLOGIES. Active RFID technologies are proprietary since there is no standard of communication between tags and readers, and come to an expensive cost. At a minimum, each active tag is about \$30, ranging up to \$100 and more per unit. On the other hand, most, if not all, passive technologies are interoperable (EPC Generation 2 or equivalent standard), which means that virtually any reader can communicate with any tag, despite the manufacturer. There are hundreds of passive manufacturers, as opposed to a few active manufacturers. Passive tags costs range from tens of cents per unit to a few dollars (e.g. \$5) per unit. Higher prices drop rapidly with order sizes.

[0041] TRACKING MOVEMENT. The passive tracking system **100** tracks the multiple and final location of the specific tagged items **112** being moved as opposed to a single location for all the existing components. All existing indoor and outdoor dynamic tracking approaches (that do not rely on stationary gates or antennas) require to scan a complete scenario in order to determine a single position of the tags via triangulation or similar type of algorithms. In the passive tracking system **100**, the multiple locations of a

tagged item **112** are measured when the tagged item **112** is actually being moved. In other words, the tagged items **112** being moved are only tracked as opposed to tracking all the tagged items **112** (at all data collection efforts). For each movement, all the locations of the specific tagged item **112**(s) are being tracked and estimated as opposed to a single location for all the tagged items **112**. Thus, there is a significant minimization of the effort, technology resources, complexity, and cost required to determine new tagged item **112** positions.

[0042] EFFICIENCY. When compared to the existing active RFID approach, the passive tracking system **100** becomes extremely more efficient, since, essentially, a tagged item **112** is only tracked when it is being moved. In the conventional active RFID approach, the current practice is to track the location of all (frequently thousands of) components one or more times a day.

[0043] PROXIMITY BEHAVIOR. The passive tracking system **100** relies on very short communication ranges from passive radio frequency devices, with signals traveling a few feet between reader and tag, and vice versa. In alternative tracking approaches that all use active technologies, the larger the communication range, the better these approaches work. Longer ranges, up to 1,000 and more feet, represent an opportunity to track more components at any given time, given that readers can capture signals from distant components and process them into positions. With a large read range, such as that of active tracking systems, the proposed passive RFID approach would not be feasible. On the contrary, in this passive RFID approach of the passive tracking system **100**, a fundamental characteristic is that for a component to be tracked, such component must be nearby the agent. Thus, in the passive tracking system **100** read ranges should not exceed a few feet. Actually, preliminary experiments have proven that, the shorter the read range, the more accurate the position results. In this innovation, the approach is based on proximity behavior. If there is proximity, there is identification, but if there is no proximity, there cannot be identification in the passive tracking system **100**.

[0044] It should be understood from the foregoing that, while particular embodiments have been illustrated and described, various

modifications can be made thereto without departing from the spirit and scope of the invention as will be apparent to those skilled in the art. Such changes and modifications are within the scope and teachings of this invention as defined in the claims appended hereto.

CLAIMS

What is claimed is:

1. A passive tracking system comprising:
 - a roving agent having a radio frequency identification receiver, the roving agent being operable for moving one or more tagged items from a first location to a second location;
 - a passive radio frequency identification tag associated with each respective one or more tagged items being moved from the first location to the second location by the roving agent, the passive radio frequency identification tag being detected by the radio frequency identification receiver when located on the roving agent; and
 - a positional receiver associated with the roving agent and synchronized with the radio frequency identification receiver of the roving agent, the positional receiver being operable to synchronize a position of roving agent when a respective one or more tagged items being moved by the roving agent is detected by the radio frequency identification receiver.
2. The passive tracking system of claim 1, wherein the first location of the roving agent is when the respective one or more of the tagged items is first located on the roving agent and the second location of the roving agent is when the respective one or more of the tagged items is no longer located on the roving agent.
3. The passive tracking system of claim 2, wherein the radio frequency identification receiver of the roving agent is operable to receive a signal from the passive radio frequency identification tag associated with the respective one or more tagged items located on the roving agent.
4. The passive tracking system of claim 1, further comprising a processor in operative communication with the radio frequency identification receiver for identifying which passive radio frequency identification tags are traveling with the roving agent.

5. The passive tracking system of claim 4, wherein the processor executes instructions for determining which of the passive radio frequency identification tags are traveling with the roving agent and which of the passive radio frequency identification tags are stationary and not traveling with the roving agent.
6. The passive tracking system of claim 4, further comprising a database in operative communication with the processor, the database including data related to the position of each respective one or more passive radio frequency identification tags.
7. The passive tracking system of claim 6, wherein the processor executes instructions in which the position of a respective one or more passive radio frequency identification tags in the database is updated when detected by the radio frequency identification receiver.
8. The passive tracking system of claim 7, wherein the position of the respective one or more passive radio frequency identification tags is the position of the roving agent when the respective one or more passive radio frequency identification tags is detected by the radio frequency identification receiver.
9. The passive tracking system of claim 1, wherein the radio frequency identification receiver is operable to detect one or more passive radio frequency identification tags when in close proximity to the roving agent and not located on the roving agent.
10. The passive tracking system of claim 1, wherein each of the one or more passive identification tags is battery-less.
11. The passive tracking system of claim 1, wherein the positional reader comprises a global positioning system.
12. A passive tracking process comprising:
 - storing in a database the identity of one or more radio frequency identification tags associated with a respective one or more tagged items detected by a roving agent;
 - reading positional data of the roving agent traveling from a first position to a second position when one or more passive radio frequency

identification tags located on the roving agent is detected by a radio frequency identification receiver of the roving agent; determining which of the one or more passive radio frequency identification tags is detected by the radio frequency identification receiver of the roving agent; and updating the location of the one or more passive radio frequency identification tags detected by the radio frequency identification receiver in the database.

13. The method of claim 12, further comprising:
 - determining whether the one or more passive radio frequency identification tags detected by the radio frequency identification receiver is stationary or located on the roving agent.
14. The method of claim 12, further comprising:
 - determining a travel path of the roving agent from the first location to the second location.
15. The method of claim 12, further comprising:
 - synchronizing the positional data with the identification of the one or more passive radio frequency identification tags.
16. The method of claim 12, further comprising:
 - determining the signal strength of the one or more passive radio frequency identification tags detected by the radio frequency identification receiver.
17. The method of claim 12, further comprising:
 - determining the travel path of the one or more passive radio identification tags based on the positional data.

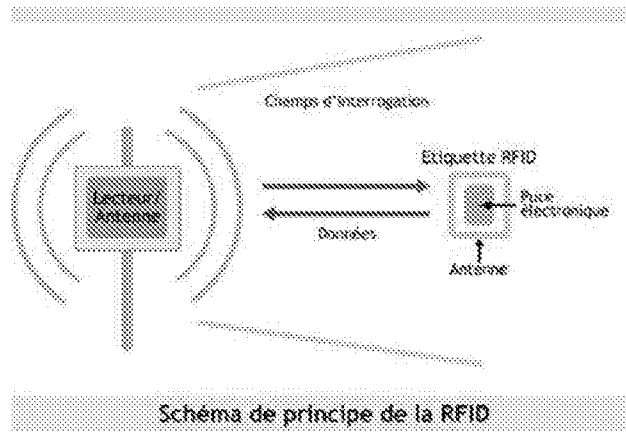


FIG. 1

(PRIOR ART)

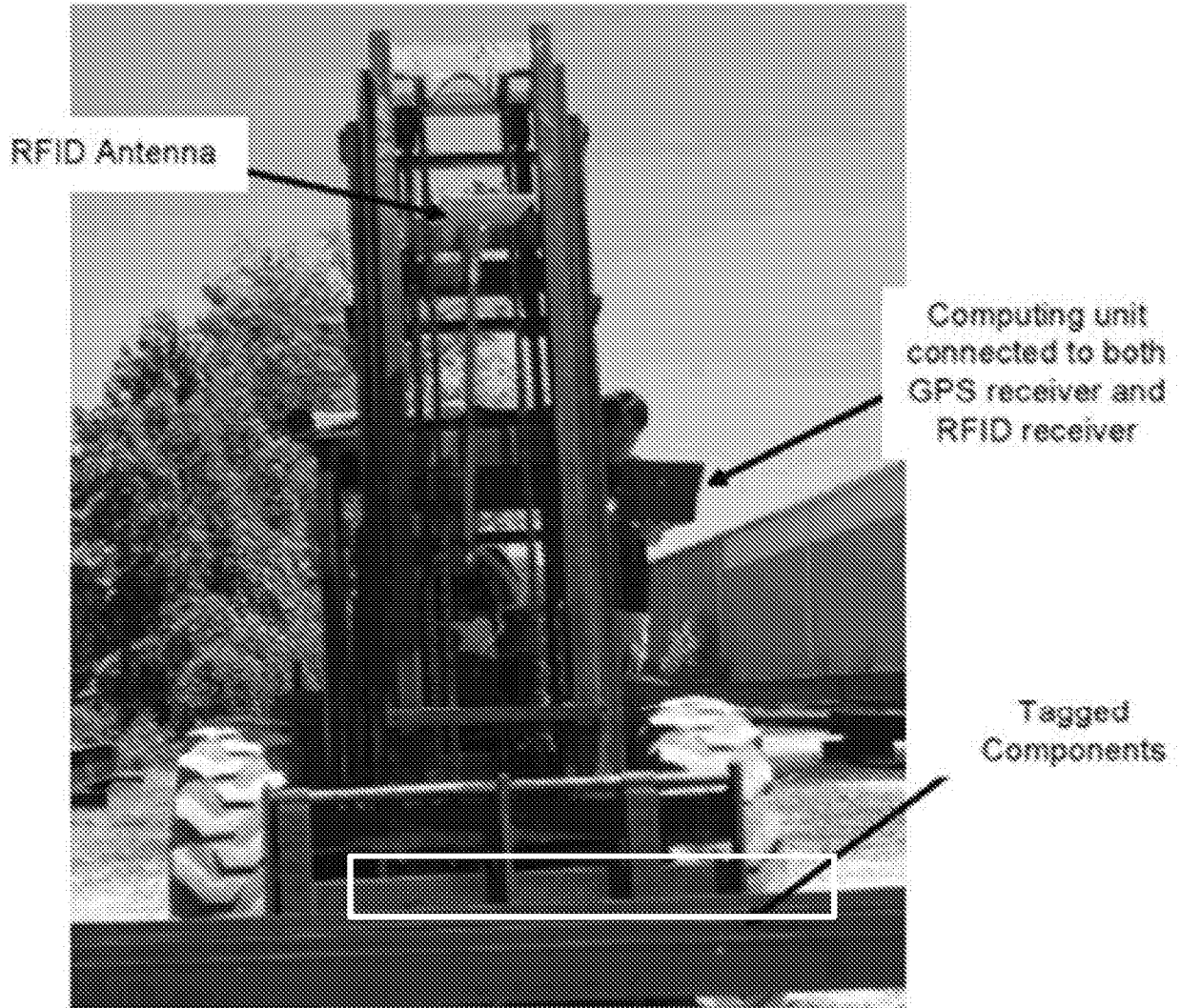


FIG. 2

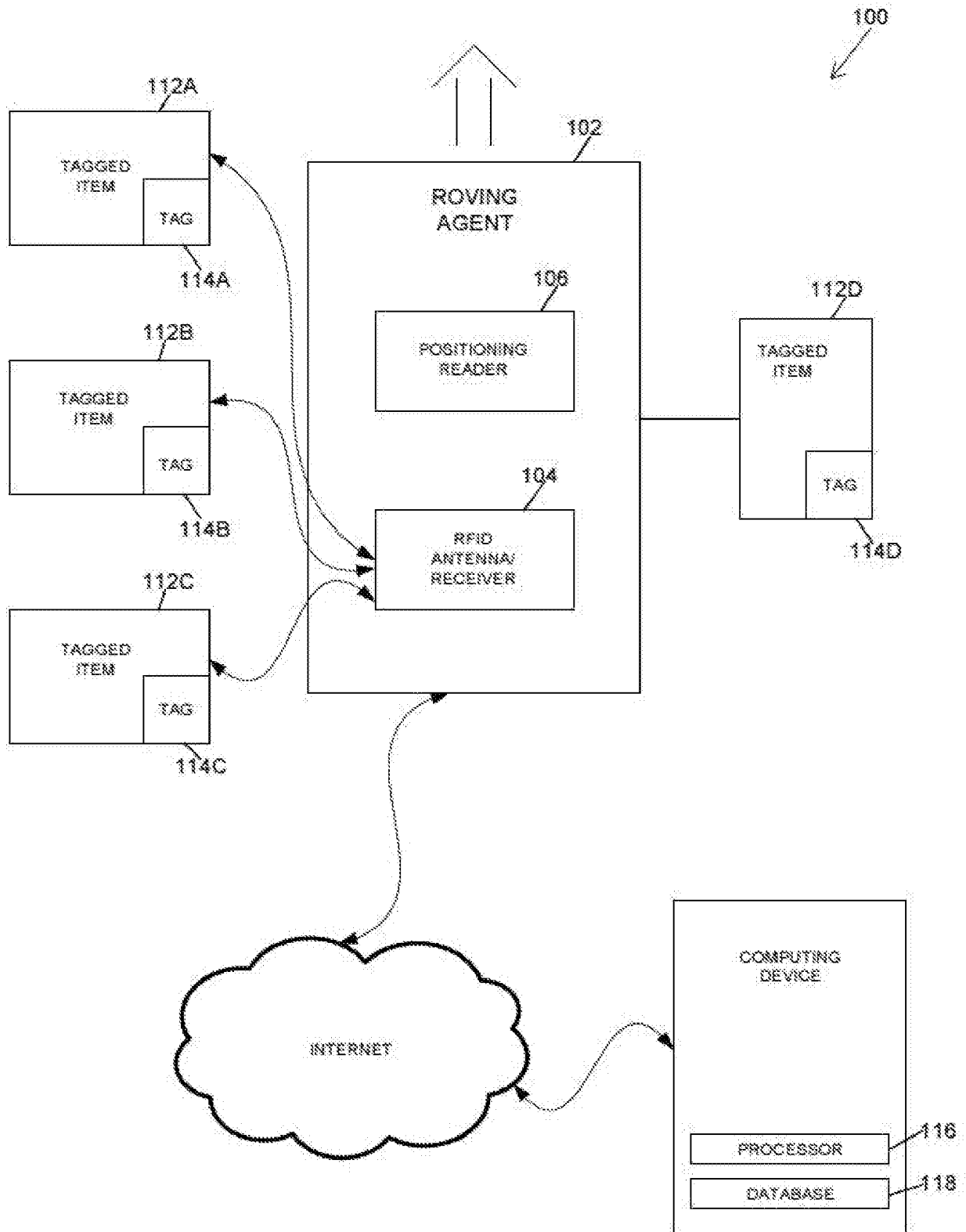


FIG. 3

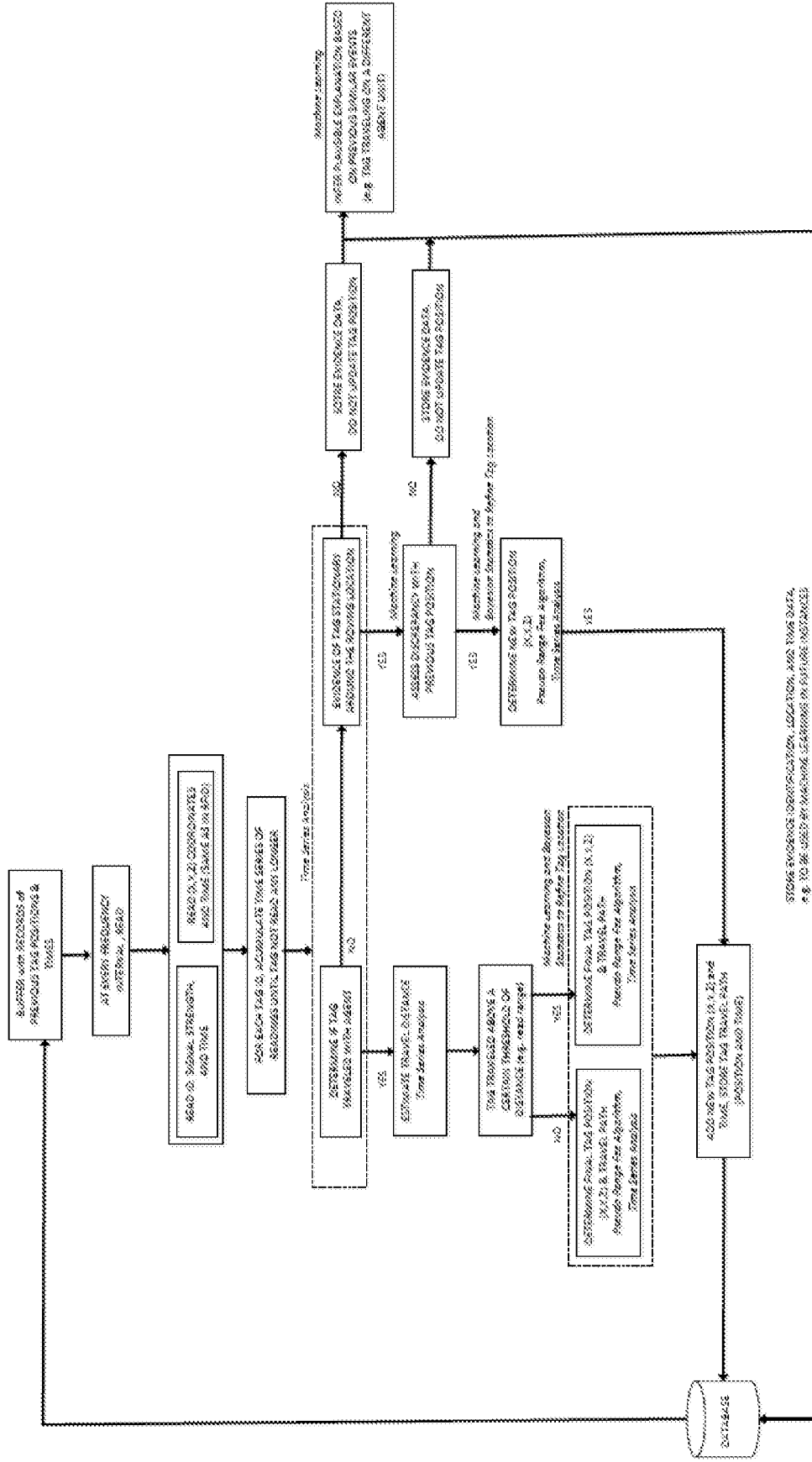


FIG. 4

A. CLASSIFICATION OF SUBJECT MATTER**G06Q 10/08(2012.01)i, G06K 19/07(2006.01)j**

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHEDMinimum documentation searched (classification system followed by classification symbols)
G06Q 10/08; H04Q 7/20; G01S 1/00; H04Q 5/22; G01S 3/02; G01S 5/02; G06K 19/07Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched
Korean utility models and applications for utility models
Japanese utility models and applications for utility modelsElectronic data base consulted during the international search (name of data base and, where practicable, search terms used)
eKOMPASS(KIPO internal) & Keywords: roving, agent, moving, RFID, tag, item, synchronize, position, database, update**C. DOCUMENTS CONSIDERED TO BE RELEVANT**

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
Y	US 2014-0074667 A1 (MICHAEL D. SMITH) 13 March 2014 See abstract, paragraphs [0026]-[0027],[0029],[0036], claims 1-2,5,7,13 and figures 1-6.	1-17
Y	KR 10-2010-0074722 A (ECOSENSE CO., LTD.) 02 July 2010 See abstract, paragraphs [0026]-[0027],[0046], claims 1,3 and figure 1.	1-17
A	US 2004-0192352 A1 (JARI VALLSTROM et al.) 30 September 2004 See abstract, paragraphs [0043],[0049], claims 1,5,9 and figure 4.	1-17
A	KR 10-2007-0076164 A (TONGMYONG UNIVERSITY INDUSTRIAL-ACADEMIC COOPERATION FOUNDATION) 24 July 2007 See abstract, claims 1-3 and figures 1-2.	1-17
A	US 6972719 B1 (CHARLES B. SWOPE et al.) 06 December 2005 See abstract, claims 1-2 and figures 1-2.	1-17

 Further documents are listed in the continuation of Box C. See patent family annex.

* Special categories of cited documents:

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"E" earlier application or patent but published on or after the international filing date

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"O" document referring to an oral disclosure, use, exhibition or other means

"P" document published prior to the international filing date but later than the priority date claimed

"T" later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention

"X" document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone

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"&" document member of the same patent family

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INTERNATIONAL SEARCH REPORT

Information on patent family members

International application No.

PCT/US2016/028915

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